

ABSTRACT

A behavior controlling apparatus by which the mobility area of a robot apparatus may be controlled in a simplified manner using plural landmarks. A landmark recognition unit 410 uniquely recognizes the landmarks to acquire the landmark position information $rPo(x,y,z)$. A landmark map building unit 420 integrates the totality of the landmark position information $rPo(x,y,z)$ sent by the landmark recognition unit 410 to build a landmark map which has integrated the geometric topology of the landmarks. Using the landmark map information $rPo \times N$, a mobility area recognition unit 430 builds a mobility area map representing a mobility area for the robot. Using the mobility area map, sent from the mobility area recognition unit 430, a behavior controller 440 controls the autonomous behavior of the robot apparatus 1 so that the robot apparatus 1 will not come out of or into the mobility area.